

IN THE SPECIFICATION:

**Please amend paragraph [0066] as follows:**

[0066] Referring to Fig. 7, the compensation controller 30 can additionally or alternatively determine a compensation force required due to pressure of the liquid and/or gas in a seal or bearing or pressure of liquid in the space. The pressures can be measured and the determination performed in a feed forward or feed back manner. For this purpose a pressure sensor 80 is provided or data from a force sensor ~~70~~ 71 can be used. Alternatively, the pressure can be determined from, for example, a knowledge of the flow rate of liquid into and/or out of the space 5. In this way the inherent variations in pressure of the immersion liquid in the space 5 due to extraction of gas/liquid mixture can be compensated.

**Please amend paragraph [0069] as follows:**

[0069] If the barrier member 10 is partly supported by another part of the apparatus other than the substrate W or substrate table WT, and is actuated in the Z direction by an actuator 70, it is possible to measure the force on the substrate W or substrate table WT from a knowledge of the force applied by the actuator 70. The actuator 70 may be a electromagnetic motor, a piezoelectric motor, a gas, hydrodynamic or hydrostatic bearing between the barrier member 10 and the substrate W and/or substrate table WT, or any other sort of actuator. Information about the forces applied by the actuators can be used to determine the force on the substrate W and used (in a feed-forward manner) to determine the compensation force required. ~~Alternatively or additionally, the element 70 may be~~ Element 71 is a force sensor 70 which outputs a signal representing the force between the barrier member and the projection system which can be used by the compensation controller to determine the required compensation force. Force sensor 71 may be used with or without actuator 70.